

## Techno India NJR Institute of Technology

Academic Administration of Techno NJR Institute

Lab Deployment

| Name of Faculty: Mr Rajkumar Soni                | Subject Code: 7EE4-22 |  |
|--|-----------------------|--|
| Subject Name: Advance control system lab         | SEM: VII              |  |
| Department: Department of Electrical Engineering |                       |  |
| Total No. of Labs Planned: 12                    |                       |  |

COURSE OUTCOMES HERE (3 OUTCOMES)

At the end of this course students will be able to:

- 1 Ability to formulate transfer function for given control system problems.
- 2 Ability to find time response of given control system model.
- 3 Plot Root Locus and Bode plots for given control system model
- 4 Ability to design Lead, Lag, Lead-Lag systems in control systems
- 5 Ability to design PID controllers for given control system model

| Labs | Name of Experiment  |
|------|---|
| No.  |   |
| 1    | Determination of transfer functions of DC servomotor and  |
|      | AC servomotor.  |
| 2    | Time domain response of rotary servo and Linear servo (first  |
|      | order and second order) systems using MATLAB/Simulink.  |
| 3    | Simulate Speed and position we fit of DC Motor  |
|      | For TECHNO HUID THAT UTZAICH  |
|      | For TECIMO Maia NARA SCOTTER OF DO WIOLOT<br>Gon ST Gran St Const<br>Dr. Pankaj Kumar Porwa'<br>(Principal) |

(Principal)

| 4  | Frequency response of small-motion, linearized model of     |
|----|---|
|    | industrial robot (first and second order) system using      |
|    | MATLAB.   |
| 5  | Characteristics of PID controllers using MATLAB. Design     |
|    | and implementation of P, PI and PID Controllers for         |
|    | temperature and level control systems;                      |
| 6  | Design and implement closed loop control of DC Motor        |
|    | using MATLAB/Simulink and suitable hardware platform.       |
| 7  | Implementation of digital controller using microcontroller; |
| 8  | Design and implementation of controller for practical       |
|    | systems - inverted pendulum system.                         |
| 9  | To design and implement control action for maintaining a    |
|    | pendulum in the upright position (even when subjected to    |
|    | external disturbances) through LQR technique in an          |
|    | Arduino Mega.   |
| 10 | The fourth order, nonlinear and unstable real-time control  |
|    | system (Pendulum & Cart Control System)                     |
| 11 | Mini project on real life motion control system             |

## **TEXT/REFERENCE BOOKS**

- 1. Smarjit Ghosh, Control Systems: Theory and Applications, 2/e, Pearson Publisher. 2004
- 2 Dhannesh N. Manik: Control System, Cengage Learning. 2012
- 3 I. J. Nagrath and M. Gopal: Control Systems Engineering, 3rd Ed, New Age Publication.
- 4 K. R. Varmah: Control Systems, MGH 2010
- 5 Anandnatrajan et. al.: Control System Risigneering, 4th ed., Scitech Pub.

Uch J UT SATURA Dr. Pankaj Kumar Porwa (Principal)